Amendments to the Specification:

Pursuant to 37 C.F.R. § 1.121(b) kindly amend the specification as follows. Amendments to the specification are made by presenting replacement paragraphs or sections marked up to show changes made relative to the immediate prior version. The changes in any amended paragraph or section are being shown by strikethrough (for deleted matter) or underlined (for added matter).

On page 7, first paragraph:

In an embodiment of the invention, a practical numerical method for reliably computing a dynamical decomposition point for large-scale systems comprises the steps of moving along a search path $\varphi_t(x_s) \equiv \{x_s + t \times \hat{s}, \quad t \in \Re^+\}$ starting from x_s and detecting an exit point, x_{ex}, at which the search path $\varphi_t(x_s)$ exits a stability boundary of a stable equilibrium point x_s using the exit point x_{ex} as an initial condition and integrating a nonlinear system to an equilibrium point x_d, and computing said dynamical decomposition point with respect to a local optimal solution x_s wherein the search path ~~direction $\hat{s}$~~ is e x_d.

On page 9, line 4:

Consider a general unconstrained nonlinear optimization problem of the form:

On page 15, lines 23-24:

Step 3 - The DDP with respect to the local optimal solution x_s and the search path ~~direction $\hat{s}$~~ is e x_d.

In the Abstract (a replacement sheet having a corrected abstract is attached to this response):

A method for obtaining a global optimal solution of general nonlinear programming problems includes the steps of first finding, in a deterministic manner, all stable equilibrium points of a nonlinear dynamical system that satisfies conditions (C1) and (C2), and then finding from said points a global optimal solution. A practical numerical method for reliably computing a dynamical decomposition point for large-scale systems comprises the steps of moving along a

search path $\varphi_t(x_s) \equiv \{x_s + t \times \hat{s}, \quad t \in \Re^+\}$ starting from x_s and detecting an exit point, x_{ex}, at which the search path $\varphi_t(x_s)$ exits a stability boundary of a stable equilibrium point x_s using the exit point x_{ex} as an initial condition and integrating a nonlinear system to an equilibrium point x_d, and computing said dynamical decomposition point with respect to a local optimal solution x_s wherein the search path ~~direction $\hat{s}$~~ is e x_d.